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1. TCP position tolerances in joint torque minimizations

Grahn, S.; Flisberg, P.; Johansson, G.; Lindberg, P.O.; Larsson, T.; Intelligent Robots and Systems, 1998. Proceedings., 1998 IEEE/RSJ International Conference on Volume 2, 13-17 Oct. 1998 Page(s):800 - 805 vol.2
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2. A numerical approach for planning robot trajectories considering collision avoidance

Van De Logt, G.; Odekerken, F.-J.; Systems, Man, and Cybernetics, 1996., IEEE International Conference on Volume 2, 14-17 Oct. 1996 Page(s):1501 - 1507 vol.2
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3. Learning accurate path control of industrial robots with joint elasticity

Lange, F.; Hirzinger, G.; Robotics and Automation, 1999. Proceedings. 1999 IEEE International Conference on Volume 3, 10-15 May 1999 Page(s):2084 - 2089 vol.3
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Akutsu, T.; Yaoi, S.; Sato, K.; Enomoto, S.; Intelligent Robots and Systems '91. 'Intelligence for Mechanical Systems, Proceedings IROS '91. IEEE/RSJ International Workshop on 3-5 Nov. 1991 Page(s):429 - 434 vol.2
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5. Cascaded control concept of a robot with two degrees of freedom driven by four artificial pneumatic muscle actuators

Hildebrandt, A.; Sawodny, O.; Neumann, R.; Hartmann, A.; American Control Conference, 2005. Proceedings of the 2005 8-10 June 2005 Page(s):680 - 685 vol. 1
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Hein, A.; Lueth, T.C.; Hommel, G.; Intelligent Robots and Systems, 1999. IROS '99. Proceedings. 1999 IEEE/RSJ International Conference on Volume 2, 17-21 Oct. 1999 Page(s):733 - 739 vol.2
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Kondak, K.; Binner, S.; Hommel, G.; Neumann, M.; Intelligent Robots and Systems, 2001. Proceedings. 2001 IEEE/RSJ Internation

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